IN THE SPECIFICATION:

Please amend the paragraph bridging pages 11 and 12 of the originally filed application as follows:

FIG. 1 is a schematic view showing a configuration of an automotive window glass mounting device according to an embodiment of this invention. A window glass mounting device 1 according to this embodiment is provided with a window glass mounting robot (hereafter, called a robot) 3 having an ~~attitude-adjustable~~ altitude-adjustable robot arm 2, which is driven, based on a control signal from a robot control section 4. This robot 3 is installed on a window glass mounting line.

Please amend the paragraph on page 12, lines 5-11 of the originally filed application as follows:

A window glass holding machine 7 is mounted at the tip of the robot arm 2, wherein the machine 7 absorbs and holds a front window glass for a windshield (hereafter, called a window glass) 6, which is mounted on a body 5 of the automobile. The ~~attitude~~ altitude of the window glass holding machine 7 can be adjusted according to the driving state of the robot arm 2.

Please amend the paragraph on page 13, lines 7-27 of the originally filed application as follows:

The pair of CCD cameras 10a and 10b, each of which photographs the vicinity of the upper portion at the side of the roof panel 9 and the upper edge of the window glass 6, are positioned symmetric with respect to an axis (refer to a Y axis in FIG. 2) passing

through the center of the window glass 6 in the up-and-down direction. On the other hand, the pair of CCD cameras 10c and 10d, which photographs the vicinity of the side portion of the window glass mounting opening 8 at the side of the windshield pillar section 11 and the edge of the window glass 6 at the right and left side respectively, are provided at the right and left edges of the window glass 6 on a line parallel to an axis (refer to an X axis in FIG. 2) passing through the center of the window glass 6 in the left and right direction. Each of the CCD cameras 10a, 10b, 10c, and 10d is installed approximately perpendicularly (in the Z-axis direction shown in FIG. 2) to the surface of the window glass 6 which is ~~absorbed~~ adsorbed and held at the window glass holding machine 7, and photographs the window glass from above approximately perpendicularly to the surface of the window glass 6.

Please amend the paragraph on page 14, lines 8-23 of the originally filed application as follows:

Using each of the slit laser beam irradiators 12a and 12b which is installed in the vicinity of the CCD cameras 10a and 10b respectively, the laser beam is irradiated across the vicinity of the upper portion the window glass mounting opening 8 at the side of the roof panel 9 and the upper edge of the window glass 6, as shown in FIG. 3, when the window glass 6 which is ~~absorbed~~ adsorbed and held at the window glass holding machine 7 is moved to a position (just above the mounting surface on the circumference of the window glass mounting opening 8) which has been instructed beforehand by the robot control section 4 with reference to the window glass mounting opening 8 of the body 5. Here, though the CCD camera 10a and the slit laser beam irradiator 12a are

shown in FIG. 3, the same holds for the CCD camera 10b and the slit laser beam irradiator 12b.

Please amend the paragraph on page 16, lines 7-18 of the originally filed application as follows:

By driving the robot arm 2 of the robot 3, under control of the robot control section 4, for the body 5 conveyed to a predetermined position on the window glass mounting line, the window glass 6 which is ~~absorbed~~ adsorbed and held at the window glass holding machine 7 at the tip of the robot arm 2 is moved to a mounting position which has been instructed beforehand for the mounting surface on the circumference of the window glass mounting opening 8 of the body 5. Then, moving operation of the window glass 6 is temporarily stopped just above (several millimeters short of) the mounting surface on the circumference of the window glass mounting opening 8.